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## **SUBSTITUTE SPECIFICATION**

**ADAPTATION OF AN AUTOMATIC DISTANCE CONTROL  
TO TRAFFIC USERS POTENTIALLY MERGING INTO THE LANE THEREOF**

**Cross-Reference to Related Application**

[0001] This application is a **national stage** of PCT/EP2004/012057 filed October 26, 2004, and based upon DE 103 58 034.4 filed on December 11, 2003 under the International Convention.

**BACKGROUND OF THE INVENTION**

**Field of the Invention**

[0002] The invention concerns a process for adapting the distance control for automatic safe following in motor vehicles to traffic users merging into their lane, as well as a device suitable for carrying out the process.

[0003] For increasing the safety and the driving comfort in the guidance of motor vehicles in traffic, these are today increasingly equipped with automatic systems for vehicle following control or safe separation control, by means of which the vehicle automatically maintains a safe separation from a preceding motor vehicle.

**Description of Related Art**

[0004] An example of a device of this general type is described in European Laid Open Publication EP0605104A1, which device includes a distance sensor, an evaluation unit and an adjustable speed influencing servo device which is under the control of control parameters calculated by the evaluation unit. The distance sensor is, for a example, a millimeter wavelength

radar, a lidar or an ultrasound sensor and senses the environment ahead of the road vehicle in order to detect objects or traffic users located therein. The sensor angle is therein generally selected such that objects on adjacent lanes can also be detected. The environment data detected by the distance sensor is transmitted to the evaluation unit, so that, having knowledge of the speed of the equipped vehicle, the speed of the other detected traffic users can be arrived at. Starting with a safe distance to be maintained, which is generally selected depending upon the speed, a speed-dependent following time  $t_f$  is computed. If the equipped vehicle has a higher speed than a recognized preceding traffic user in the same lane, then the following time  $t_f$  continuously decreases. If this decrease reaches a preset threshold, then the evaluation unit produces a control parameter or signal which acts on the speed governing servo device in such a manner that the speed of the equipped vehicle is reduced. The distinction as to whether an object or a traffic user is located in the same lane or an adjacent lane occurs herein on the basis of a defined lane breadth. Besides the observation of traffic users in the lane being driven by the equipped vehicle, the evaluation unit determines, using the data from the distance sensor, also the direction of movement of the traffic users in adjacent lanes. If the traffic user moves from an adjacent lane into the defined lane breadth, then the evaluation unit evaluates this traffic user as closest traffic user and controls the speed of the equipped vehicle to be so far below it that the following time  $t_f$  is maintained with respect to this traffic user. This control operation however, in particular in "pincers" movements (hazards closing in from both sides of the equipped vehicle), frequently leads to an abrupt reduction in the speed of the equipped vehicle, since traffic users changing into lane of other traffic frequently leave only a very small spacing between vehicles following behind them in their lane.

**[0005]** In order to attenuate or cushion this type of abrupt speed change, it is proposed in German Laid Open Publication DE10160189A1, to design the rules of behavior of the system for automatic following guidance in such a manner that upon detecting a traffic user in the vicinity of a road merger or junction it takes note of this fact and in connection therewith recognizes that the ahead lying road area approaches the own lane. Subsequently an increased alertness of the area detected by the distance sensor is observed for merging vehicles. On the basis of the recognition that a potential merging vehicle is located in the immediate vicinity, it can be more rapidly and reliably detected already in the first detection cycle in which it is recognized by the distance sensor and identified as such. In this manner a relevant merging vehicle can already be recognized very early, so that more time remains for adjusting the following time  $t_f$  and as a result the speed of the equipped vehicle is reduced less abruptly.

**[0006]** For increasing the time necessary for adjusting the following time  $t_f$  and for creating a more comfortable following guidance conforming more closely to the human driving behavior of a vehicle, it is proposed in German Patent DE198 04 944C2 to detect the transverse acceleration of a traffic user located in the adjacent lane and approaching the lane of the equipped vehicle. If herein a transverse speed of a traffic user located in an adjacent lane towards the equipped vehicle is detected, then a conclusion is drawn as to an imminent merging. Accordingly, here also the environment area observed by the distance sensor is widened, in order to better observe this merging vehicle. Since, as a result of the evaluation of the transverse speed, a merging of a traffic user can be recognized on the basis of its change in position already prior to the merging thereof into the lane of the distance regulated vehicle, the control process can be improved and be adapted to the driving behavior of a human motor vehicle operator. In

situations in which the merging traffic user however undertakes a relatively rapid lane change, it could also happen that, in the vehicle safe distance guidance described in DE19804944C2, an abrupt speed change of the vehicle could not be avoided.

### SUMMARY OF THE INVENTION

[0007] The task of the invention is thus to provide a process for adaptation of an automatic safe following distance guidance of a vehicle (10) to a traffic user merging into ones own lane (B), as well as a device suitable for carrying out this process, which avoids abrupt speed changes of the vehicle in the adjustment of the following time to the traffic user and to imitate the driving behavior of a human motor vehicle operator.

[0008] This task is solved by a process and by a device suitable for carrying out the process. Advantageous embodiments and further developments of the invention are described in the dependent claims.

[0009] In this new process for adaptation of an automatic following guidance of a road vehicle (10) to a traffic user (20) merging into ones own lane (B), objects and traffic users (20) ahead of their own vehicle are detected within a detection area (12) originating from a separation sensor. Subsequently in an evaluation unit the position and speeds of the detected objects and traffic users (20) are determined, in order to, beginning with this computed data, to produce controlled parameters in order to specifically act on servo means for acceleration or deceleration of the vehicle. In inventive manner, for this in the generation of the controlled parameters supplementally taken into consideration, besides the data regarding the object and the traffic

users (20) ascertained in the evaluation unit also information from a navigation system describing the course of the road ahead or a data bank containing information regarding the course of the road is accessed. In the case that it is determined that, from the information regarding the further course of the road, that at least one of the detected traffic users in normal driving behavior would change to the lane (B) of the vehicle (10), the controlled parameters for the servo means acting on the vehicle (10) are produced in such a manner, that the driving behavior of the road vehicle (10) adapts to the at least one detected traffic user (20) depending upon its vehicle speed and/or position. Included in the typical information regarding the further course of the road, from which it can be determined, that a traffic user detected therein in the normal vehicle behavior would change to the lane (B) of the vehicle, there belong in particular information regarding junctions, highway on ramps or reduction in available lanes; for example the narrowing of a three lane highway to a two lane highway, in which the vehicles located on the lane which ends must merge into an adjacent lane.

[0010] The invention therewith which makes it possible, from recognition of the own vehicle position and with reference to supplemental additional information describing the course of the road in a mode and manner looking to the future to already early so adjust the speed of the vehicle that for a potential merging traffic already early place has been provided, which leads to a significantly more harmonious driving behavior. In this advantageous manner the operator of the motor vehicle has the feeling that the system drives by looking ahead in the manner of an ideal human driving behavior.

[0011] In the frame work of the invention for the production of object data from the environment of the inventive system including the motor vehicle all types of separation sensors known from the state of the art can be employed, in particular advantageously millimeter wave length radars, lidars or distance resolving camera systems. In particularly advantageously manner information describing the ahead lying course of the street from the ADAS (Map Advanced Driver Assistance System) can be read, which besides the information necessary for vehicle navigation also includes supplemental information regarding the number of lanes (AB) and/or marking with respect to on and off ramps (C) on highways or major streets. From this type of map material, as well as from knowing the position of the vehicle it is possible using the ADAS-Maps relatively precisely to determine for example the position of on ramps, sense their locational positioning is relatively precise. If in the course of the street lying ahead of the own vehicle for example an on ramp is recognized and if in this on ramp a traffic user is recognized, it can be assumed, that this will merge accordingly to conventional driving behavior from the on ramp onto the thereto adjacent lane. If the on vehicle is located on this adjacent lane, then it can already, in contrast to the systems known from the state of the art, already before the recognized traffic user even has begun the merging process, by suitable adjustment of the servo parameters the on vehicle can be controlled or regulated in such a manner in its speed that for the ahead line merging of the other traffic user space can be made available.

[0012] If on the other hand it is recognized from the information from the navigation system describing the ahead line course of the road or from another data bank (for example the ADAS-Map) that an on ramp leads to an additional lane running parallel to the previous lane, then the evaluation unit does not exert influence by the production of servo or controlled parameters on the speed of the own vehicle. The progression guidance does not react in this type

of this situation to the recognized traffic user, since in the case of a conventional mode of driving the traffic user it is not reliably recognized that the traffic user will carry out a lane change; in such a situation the human driver of the own vehicle will also not react to this traffic user with a change of the vehicle speed, rather he would maintain the vehicle speed and only carefully observe the driving behavior of the other traffic user.

### **BRIEF DESCRIPTION OF THE DRAWINGS**

**[0013]** Of course the functionality of the invention is not limited to the forward looking recognition of merging behavior on on-ramps, but can rather for example in the same manner also be employed advantageously in situations in which in the ahead lying course of the road the number of drivable lanes is reduced and wherein the traffic users located on the disappearing lane must merge to the remaining lanes.

**[0014]** In the following the invention will be described in greater detail on the basis of illustrative examples and with aid of the figures.

Fig. 1. Shows a merging situation on an on ramp on a multi-lane road.

Fig. 2. Shows the scene corresponding to Fig. 1, in which vehicles involved in the merging process are located at other positions.

Fig 3. Likewise shows the scene corresponding to Fig 1 or 2, in which the vehicles involved in the merging process are again located at other positions.

Fig 4. Likewise shows a scene corresponding to Figs. 1, 2 or 3, in which the merging vehicles are located in the dead zone area of the merging vehicle.



**DETAILED DESCRIPTION OF THE INVENTION**

**[0015]** A typical merging situation on an on ramp of a multi-lane road is illustrated in Fig. 1. For this a vehicle **10** moves along a multi-lane road with lanes A and B on lane B in the direction of the directional arrow **11**. The C corresponds to an on and off ramp onto the roadway with the lanes A and B. The vehicle **10** is equipped with an inventive system for recognition of merging vehicles, wherein the limitations of a for example sensing or detection range of the separate sensor included in the system is indicated by dashed lines **12**. In the examples shown in Figs. 1 through 4 the sensing area of the separation sensor is so arranged that it overlaps wide areas of lanes A, B, and C. A vehicle **20** is moving along lane C, which is located in the sensing area **12** of the separation sensor and therewith is detected by the inventive system. Based on the assumption of a typical driving behavior it is then to be presumed, that the vehicle **20** will change from lane C to lane B along a trajectory **21a** or **21b** or **21c** (or a similar trajectory). Whatever the possible trajectory is selected by the driver of the vehicle in the course of his change or merging process is selected cannot be predicted in a situation as illustrated in Fig. 1, since the vehicle is still driving straight ahead and therewith no significant transverse movement can be measured. By means of the evaluation of the sensor data of the separation sensor however the relative speed of the vehicle **20** can be measured in reference to the own vehicle **10**.

**[0016]** In order to allow vehicle **20** a optimal, interference free merger process it is possible in advantageous manner in those cases, in which the speed of the at least one detected traffic user **20** exceeds the own speed of the vehicle **10**, to so adapt the driving behavior of the own vehicle **10** to that of the traffic user **20**, that by a suitable adjusting of the servo parameter the speed of the own vehicle **10** is reduced to the realm of the speed of the traffic user **20**. (In the case of the speed of the detected traffic user **20** is exceeded by the own speed of the own vehicle

10). In this manner, the distance between the two vehicles remains essentially constant, so that the driver of the 10 does not experience an uncomfortable approaching to the vehicle 20, and also the operator of the vehicle 20 is implicitly telegraphed the possibility of a safe merger.

[0017] In order to optimize the driving behavior of the vehicle 10 in its breaking behavior, the relative speed of the vehicle 20 relative to vehicle 10 should be taken into consideration in determining the servo parameters for the vehicle brake system. Therein it is advantageous when the separation of the own vehicle 10 to the at least one detected traffic user 20 is so large, that the reduction and speed of the own vehicle 10 occurs with moderation. Here the operator of the own vehicle 10 is not disturbed by oscillations in distance between the vehicles or a moderate approaching of the own vehicle to the other vehicle 20 and corresponds essentially to his own natural driving behavior. In those cases, as shown for example in Fig. 2, in which the distance of the owned vehicle 10 is relatively small to the at least one detected traffic user 20 and wherein he in accordance with a conventional driving behavior would quickly carry out a change in lane maneuver, the reduction and speed of the own vehicle 10 can advantageously occur rapidly. In the here shown example the other vehicle 20 is located close to the end of the on ramp, so that, in accordance with conventional driving behavior, it can be presumed, that the merging maneuver from lane C to lane B would occur very soon along trajectory 22. Alternatively to a rapid dropping of the vehicle speed of the own vehicle 10 this could in advantageous manner also be so controlled, that a change in lane to an adjacent, away from the detected traffic user 20 (here: lane A) is carried out along for example trajectory 13. Such a behavior, the avoidance of danger, corresponds to the natural behavior of the vehicle operator and is thus not found to be a cause of concern by him.

[0018] If this type of change in lane occurs completely automatically, it should be insured, that prior to the change in lane to the lane opposite to the traffic user 20, the adjacent lane A, is checked for avoidance of accidents by means of a sensor system for monitoring adjacent lanes a blind angle monitoring system, it is checked with regard to whether a free of danger change of the own vehicle 10 to lane A is possible.

[0019] The result of a checking and monitoring of this type of the occupancy condition of a possible evasion lane can lead to a decision regarding suitable means for reaction to a eminent merging vehicle 20; that is it can be decided whether the operator of the vehicle 10 would prefer a rapid breaking of his own vehicle or whether a deviation to lane A would be considered more natural and comfortable.

[0020] In Fig. 3. a traffic situation is illustrated, in which the separation of the own vehicle 10 to the at least one traffic user 20 in the detection area 12 is relatively small, it however in accordance with the conventional driving behavior still has time remaining for a lane change, the speed of the own vehicle 10 is not reduced since vehicle 10 moves in general substantially faster than the other vehicle 20 it will speedily over take this, so that the operator of the other vehicle 20 can merge behind 10 onto lane B without problem. In an advantageous manner it is however also conceivable, in a situation of this type to moderately increase the speed of the own vehicle 10, if the traffic situation or the traffic regulations or a setting of the cruise control system (Tempomat, DISTRONIC) permit this. In this manner on the one hand the own vehicle 10 distances itself substantially more rapidly from the potential dangerous situation and on the other hand the operator of the other vehicle 20 is given more time for merging, since the lane B is more rapidly opened. If vehicle 10 however is accelerated in advantageous manner the speed thereof should, after passing the other traffic user 20 can be reduced to the speed at which it

operated prior to over taking. By this return controlling of the speed the vehicle 10 continues, despite the merger maneuver of an another vehicle on to his lane, continues on its way with the accustomed behavior.

[0021] Fig. 4 shows a further merger situation of an on ramp. Herein the own vehicle 10 moves along a multi-lane highway with lanes A and B along lane B in the direction of the indicating 11. On the same lane A there is supplementally a vehicle in traffic 30, which moves in the direction of the indicating arrow 31. A further vehicle 20 moves along lane C, this is however located in the blind area of the own vehicle 10 and is detected by a blind angle monitoring system integrated in the own vehicle 10. Under the assumption that the other vehicle 20 is moving faster than the own vehicle 10, it is to be presumed, that the other vehicle 20 will change lane from C to lane B along the trajectory 24 or similar trajectory between the vehicles 10, 30. In the case that the distance between the vehicles 10, 30 is large or that no preceding vehicle 30 is present, a moderate reduction of the speed of the own vehicle 10 suffices, so that the other vehicle 20 can merge with a safe distance ahead of the own vehicle 10. A substantial reduction is herein brought about thereby, in that for a short time no gas is given. In a case that the vehicles 10, 30, move along with approximately the same speed and follow close to each other, space must be provided for the merger of vehicle 20. The in case it is determined from the view of the vehicle 10 by means of a blind angle monitoring system that no vehicular traffic is located on lane A, it can be presumed, that the vehicle 20 immediately after merging on to lane B will continue changing lane to lane A, so that a stronger engagement of breaks can be extended for a short period of time in vehicle 10. In contrast, in the case that the adjacent lane A is already occupied a stronger actuation of the breaks is brought about in vehicle 10 without delay.

[0022] In particularly advantageous manner the inventive process and the inventive device allow themselves to be used to merge from a lane traveled by a vehicle 10 containing the invention to an adjacent lane, upon which other traffic users are located. Herein it is in particular with access to the environment information from the adjacent street areas decided whether the vehicle 10 should merge ahead of or after in particular traffic user traveling there. Depending upon this decision one sets the speed of the own vehicle either above or below the speed of the concerned vehicle participant by suitable selection of the adjustment parameter for the servo means for acceleration or breaking of the own vehicle, so that a safe merger procedure representing a far-sided manner of driving is safely carried out to the adjacent lane.

[0023] Now that the invention has been described, we claim: